

In the Claims:

Please amend the claims as follows:

1-10 (cancelled)

11. (new) An industrial robot manipulator, comprising:

a first arm comprising a front arm part and a rear arm part, the front arm part being journaled in the rear arm part such that the front arm part is rotatable about a first axis relative to the rear arm part;

cabling extending along the front arm part and the rear arm part; and

a supporting device operative to support the cabling, the supporting device comprising

a supporting arm arranged in the vicinity of the rear arm part and rotatably

supported about a second axis, and

an auxiliary arm operatively connected to the front arm part,

wherein the supporting arm applies a spring pulling force on the cabling in a longitudinal direction of the cabling.

12. (new) The manipulator according to claim 11, further comprising:

a first attachment operatively connected to the rear arm part and operative to receive the cabling.

13. (new) The manipulator according to claim 11, further comprising:

a second attachment operatively connected to the auxiliary arm and operative to receive the cabling.

14. (new) The manipulator according to claim 12, wherein a first attachment is arranged at a distal end of the supporting arm.

15. (new) The manipulator according to claim 12, wherein the first attachment surrounds the cable.

16. (new) The manipulator according to claim 13, wherein the second attachment surrounds the cable.

17. (new) The manipulator according to claim 11, wherein the supporting device winds the cabling around the front arm part when the second arm is rotated.

18. (new) The manipulator according to claim 11, wherein the first axis and the second axis are perpendicular to each other.

19. (new) The manipulator according to claim 11, further comprising:
a spiral spring operative to rotate the supporting arm about the second axis to apply the spring force to the cabling.

20. (new) The manipulator according to claim 19, further comprising:

a casing operative to protect the spring.

21. (new) The industrial robot according to claim 20, wherein the casing is a tensioning element operative to tension the spring.

22. (new) The industrial robot according to claim 11, wherein the supporting arm is connected in the vicinity of a proximal end of the rear arm part of the first arm.

23. (new) The industrial robot according to claim 11, further comprising:
a rigid tube arranged between the supporting arm and the auxiliary arm and enclosing the cabling.

24. (new) The industrial robot according to claim 23, wherein the tube is bendable.

25. (new) The industrial robot according to claim 11, further comprising:
snap-in cable attachments provided on the supporting arm and the auxiliary arm.

26. (new) The industrial robot according to claim 11, wherein the supporting arm comprises an angle part operative to permit the cabling to be supported centrally over the first arm.

27. (new) The industrial robot according to claim 11, wherein the supporting arm lifts the cabling.

28. (new) The industrial robot according to claim 11, wherein upon rotation of the front arm part about the first axis the cabling is wound around the front arm part.

29. (new) The industrial robot according to claim 11, wherein the supporting arm comprises a plurality of arms arranged in a four-linkage system.

30. (new) The industrial robot according to claim 11, further comprising:
a spring arrangement operative to apply a spring force to the supporting arm.

31. (new) The industrial robot according to claim 30, wherein the spring arrangement comprises a torsion spring, a tensile spring, or a compression spring.

32. (new) A method for supporting and manipulating cabling of an industrial robot, the method comprising:

supporting cabling on a supporting device operative to support the cabling between a front arm part of a first arm and a rear arm part of the first arm; the front arm part being journaled in the rear arm part such that the front arm part is rotatable relative to the rear arm part about a first axis; the rear arm part being rotatable about a second axis; the supporting device comprising a supporting arm rotatably supported about a second axis arranged in the vicinity of the rear arm part, and an auxiliary arm connected to front arm part;

applying a spring pulling force on the cabling with the supporting device in a longitudinal direction of the cabling; and

manipulating the front arm part and the rear arm part.

33. (new) A method of manufacturing an industrial robot, the method comprising:

providing a first arm comprising a front arm part and a rear arm part, wherein the front arm part is journaled in the rear arm part such that the front arm part is rotatable with respect to the rear arm part about a first axis;

rotatably connecting a supporting arm of a supporting device about a second axis arranged in the vicinity of the rear arm part;

connecting an auxiliary arm of the supporting device to the front arm part;

extending cabling between the supporting arm and the auxiliary arm; and

applying with the supporting device a spring pulling force on the cabling in a longitudinal direction of the cabling.